

Abstract

The traffic situation may be recorded by way of at least two detection cameras (2, 3) which are to be arranged at a distance (15) to one another on a vehicle (1). Their detection regions (11, 12) overlap (13), by which means at least one reference point (R) of the surroundings and/or recognition point of at least one second vehicle may be triangulated (T), e.g. by way of photogrammetry. After an accident, the behaviour of one or more vehicles (1) may be reconstructed. By way of the three-dimensional, temporally cycled detection, apart from the respective spatial position, the speed, the speed direction, direction changes, acceleration- and braking manoeuvres as well as intrinsic rotations of the individual vehicles about their centres of gravity may be visible and measured in a scaled manner. And this is all possible without having a multitude of sensors on the vehicles. The vehicles (1) may also be projected into a 3D picture of the surroundings, and thus a virtual representation from any viewers perspective may be computed and displayed.